

substantially aligning a leading edge of each digital signal in said reference pulse train with  
10 a leading edge of each digital signal in said feedback pulse train;  
generating a control signal dependent upon said comparison, said generating step including  
the substeps of:  
generating a proportional error pulse train including a plurality of digital  
signals, each said digital signal representing an error between a corresponding pair  
15 of aligned digital signals of said reference pulse train and said feedback pulse train;  
counting up from zero with a first proportional clock CP1 at a frequency  
fP1 when said digital signals of said proportional error pulse train are in a high  
state;  
resetting said first proportional clock CP1 to zero when said digital signals  
20 of said proportional error pulse train are in a low state;  
loading a current value of said first proportional clock CP1 into a second  
proportional clock CP2 each time said first proportional clock CP1 transitions from  
a high state to a low state;  
counting down from said loaded current value with said second  
25 proportional clock CP2 at a frequency fP2 until a zero value is reached; and  
determining a proportional error term representing a time average of a  
signal which is held high while said second proportional clock CP2 is in a high state  
and held low while said second proportional clock CP2 is in a zero state, said  
control signal being dependent upon said proportional error term; and  
30 providing said control signal as an input to said target system.

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6. (Amended) A method of regulating a target system, comprising the steps of:

providing a reference signal;

generating a plurality of digital signals defining a reference pulse train with a frequency dependent upon said reference signal;

5 providing a target system to be regulated, said target system having an output in the form of a plurality of digital signals defining a feedback pulse train having a frequency;

comparing said frequency of said reference pulse train with said frequency of said feedback pulse train, and substantially aligning a leading edge of each digital signal in said reference pulse train with a leading edge of each digital signal in said feedback pulse train;

10 generating a control signal dependent upon said comparison, said generating step including the substeps of:

generating a proportional error pulse train including a plurality of digital signals, each said digital signal representing an error between a corresponding pair of aligned digital signals of said reference pulse train and said feedback pulse train;

15 generating an error direction pulse train including a plurality of digital signals, each said digital signal representing a directionality of said error between said corresponding pair of aligned digital signals;

counting up from zero with a first integral clock CI1 at a frequency f11 when said digital signals of said proportional error pulse train are in a high state and said digital signals of said error direction pulse train are simultaneously in a high state;

20 counting down with said first integral clock CI1 at said frequency f11 when said digital signals of said proportional error pulse train are in a high state and said digital signals of said error direction pulse train are in a low state;

25 maintaining said first integral clock CI1 at a current value when said digital  
signals of said proportional error pulse train are in a low state;

loading a current value of said first integral clock CI1 into a second integral clock CI2 each time said first integral clock CI1 transitions from a high state to a low state;

30 counting down from said loaded current value with said second integral  
clock CI2 at a frequency fI2 until a zero value is reached; and

determining an integral error term representing a time average of a signal which is held high while said second integral clock CI2 is in a high state and held low while said second integral clock CI2 is in a zero state, said control signal being dependent upon said integral error term; and

35 dependent upon said integral error term; and

providing said control signal as an input to said target system.

7. (Amended) A method of regulating a target system, comprising the steps of:

providing a reference signal;

generating a plurality of digital signals defining a reference pulse train with a frequency

dependent upon said reference signal;

5 providing a target system to be regulated, said target system having an output in the form  
of a plurality of digital signals defining a feedback pulse train having a frequency;

comparing said frequency of said reference pulse train with said frequency of said feedback pulse train, and substantially aligning a leading edge of each digital signal in said reference pulse train with a leading edge of each digital signal in said feedback pulse train;

generating a control signal dependent upon said comparison, said generating step including  
the substeps of:

generating a proportional error pulse train including a plurality of digital signals, each said digital signal representing an error between a corresponding pair of aligned digital signals of said reference pulse train and said feedback pulse train;

15 counting up from zero with a first derivative clock CD1 at a frequency fD1 when said digital signals of said proportional error pulse train are in a high state;

subtracting a current state of said first derivative clock CD1 from a current state of a register R each time said first derivative clock CD1 transitions from a high state to a low state;

loading said subtracted state into a second derivative clock CD2;

loading said current state of said first derivative clock CD1 into said register R;

resetting said first derivative clock CD1 to zero;

counting down with said second derivative clock CD2 at a frequency fD2

25 after said subtracted state is loaded therein;

maintaining said first integral clock CI1 at a current value when said digital signals of said proportional error pulse train are in a low state; and

determining a derivative error term representing a time average of a signal

which is held high while said second derivative clock CD2 is in a high state and held low while said second derivative clock CD2 is in a zero state, said control signal

30 being dependent upon said derivative error term; and

providing said control signal as an input to said target system.